

**IN THE CLAIMS:**

Please AMEND claims 1-3 and 6-10, as shown below.

1. (Currently Amended) A robot hand apparatus comprising:

a base;

a motor fixed to the base;

a first link which is supported by the base while allowing ~~a~~the rotation around a first axis and which has a first guide path in which a control axis is movable, the first axis is in parallel to an actuation axis of the motor and is positioned apart from the actuation axis;

a second link which connects with the actuation axis of the motor and supports the control axis, and which moves the control axis within the first guide path in accordance with ~~a~~the rotation of the actuation axis of the motor; and

a finger link which is supported by the first link while allowing ~~a~~the rotation around a second axis crossing the first axis, the finger-link directly or indirectly connects with the control axis so that the finger-link is rotated around the second axis in accordance with the actuation of the control axis.

2. (Currently Amended) A robot hand apparatus according to claim 1, wherein

the base has a second guide path within the moveable range of the first guide path,  
and

the second link includes:

a rotator fixed to the actuation axis; and

a connection link which is rotatably supported by the rotator and supports  
the control axis.

3. (Currently Amended) A robot hand apparatus according to claim 2,  
wherein

the second guide path is formed by connecting a first guide hole, which elongates  
in a ~~circumference~~ direction around a circumference of the first axis, and a second guide  
hole, which elongates in a ~~radial~~ direction of a radius of with respect to the first axis.

4. (Original) A robot hand apparatus according to claim 3, wherein  
the first guide hole guides the control axis in a circumference direction around the  
first axis, and

the second guide hole guides the control axis in a radial direction with respect to  
the first axis.

5. (Original) A robot hand apparatus according to claim 3, wherein

the control axis is adapted to slide within the first guide hole and the second guide hole.

6. (Currently Amended) A robot hand apparatus according to claim 2, wherein

the position where the connection link is supported ~~by~~of the rotator is an eccentric position with respect to the position where the actuation axis is fixed to the rotator.

7. (Currently Amended) A robot hand apparatus according to claim 5, wherein

a protrusion, which contacts with a protruding part ~~25~~ provided on the base and controls the rotation of the rotator, is provided ~~on~~to the rotator, ~~and wherein~~

the position where the protrusion is provided is the position opposite across the position where the actuation axis is fixed to with regard to the position where the connection link is supported to.

8. (Currently Amended) A robot hand apparatus according to claim 3, wherein

the first guide path is a long hole which elongates in a ~~radial~~ direction of a radius ~~of with respect to~~ the control axis.

9. (Currently Amended) A robot hand apparatus according to claim 8, wherein

the elongation direction of the first guide path agrees with the elongation direction of the second guide hole of the second guide path when the finger link is rotated around the second axis.

10. (Currently Amended) A robot hand apparatus according to claim 9, wherein

a lifting member, which connects with the control axis and moves together with the control axis when the control axis moves along the second guide path, is provided to the connection link, and

the lifting member is provided with an arm member which rotatably connects the finger link and rotates the finger link around the second axis.